EAST Search History

EAST Search History (Prior Art)

Ref #	Hits	Search Query	DBs	Default Operator	Plurals	Time Stamp
S39	44	S35 and S38	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/05/21 22:41
S38	3619	print$3 with robot	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/05/21 22:41
S37	185	S35 and S36	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/05/21 22:41
S36	85494	("347").CLAS.	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	OFF	2010/05/21 22:41
S35	3958	rail and rotat$3 and (head printhead print $1head print adj head) and degree near2 freedom	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/05/21 22:41
S41	107	robot$2 with arm with wrist same degree near3 freedom same rotat$3	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/05/21 22:50

S40	12	robot$2 with arm with wrist same degree near3 freedom same (rotational rotat $3) same (translational translat$3)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/05/21 22:50
S43	70	(start begin) with (eject$3 print$3) with (lower bottom) with (left left$1hand lefthand left adj hand) with (page sheet paper medium substrate surface)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/05/21 22:51
S42	187	drying with (ultraviolet ultra $1violet UV) adj (fluid liquid ink)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/05/21 22:51
S46	107	robot$2 with arm with wrist same degree near3 freedom same rotat$3	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/05/21 22:52
S45	677	(347/2).CCLS.	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	OFF	2010/05/21 22:52
S44	498	(347/8).CCLS.	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	OFF	2010/05/21 22:52

EAST Search History (Interference)

Ref #	Hits	Search Query	DBs	Default Operator	Plurals	Time Stamp

| L4 | 5 | (print$3 and (robot wrist arm) and carriage and (rail beam) and rotat$3 and (axis axes) and (freedom movement)).clm. | US-PGPUB; UPAD | OR | ON | 2010/05/21 23:25 |
| L3 | 9 | (print$3 and (robot wrist arm) and carriage and (rail beam) and rotat$3 and (axis axes)). clm. | US-PGPUB; UPAD | OR | ON | 2010/05/21 23:25 |

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print robot with carrier and wrist.wsp